

the purpose of describing particular embodiments only, and is not intended to be limiting.

What is claimed is:

1. A method comprising:

receiving, by a command robot, sensory data captured by a first client robot, wherein the command robot is in communication with the first client robot and a second client robot, wherein the first client robot has a first sensing capability and the second client robot has a second sensing capability that is different than the first sensing capability, wherein the sensory data is captured by way of the first sensing capability of the first client robot, wherein the first client robot has a first functionality and the second client robot has a second functionality that is different than the first functionality, wherein the sensory data is relevant to the second functionality of the second client robot;

providing, by the command robot, at least a portion of the sensory data captured by the first client robot as a first input to the second client robot, wherein the portion of the sensory data is relevant to the second functionality of the second client robot;

receiving feedback from the second client robot based on the first input; and

commanding, by the command robot, the second client robot to perform a task by way of the second functionality based on the feedback and the portion of the sensory data captured by the first client robot.

2. The method of claim 1, further comprising:

receiving further sensory data from the first client robot; and

commanding the first client robot to perform an additional task based on the further sensory data.

3. The method of claim 1, wherein each of the first client robot and the second client robot include at least one sensor comprising one or more of an image capture device, an acoustic sensor device, and an electronic data acquisition device.

4. The method of claim 1, wherein the first sensing capability is related to capturing environment sensory data associated with a condition of an environment of the first client robot, and wherein the second sensing capability is related to sensing state of a device configured to adjust the condition of the environment of the first client robot.

5. The method of claim 1, further comprising:

receiving respective sensory data from the second client robot based on the commanded task, wherein the respective sensory data is captured by the second client robot by way of the second sensing capability; and

in response to the receiving the respective sensory data, commanding the second client robot to provide a second input to the first client robot indicating performance of the commanded task.

6. The method of claim 1, wherein the command robot is in communication with the first client robot and the second client robot by way of a cloud computing system, wherein the cloud computing system includes at least one server remote from the command robot, the first client robot, and the second client robot, and wherein the at least one server is configured to store at least a portion of the sensory data and facilitate communication between the command robot and the first and second client robots.

7. The method of claim 1, wherein at least one of the first client robot and the second client robot comprises one or

more mechanical actuators and configured to receive a removable module that includes wireless communication capability, wherein the command robot is configured to communicate with the at least one of the first client robot and the second client robot by way of the wireless communication capability.

8. A non-transitory computer readable memory having stored thereon instructions that, when executed by a command robot, cause the command robot to perform operations comprising:

receiving sensory data captured by a first client robot, wherein the command robot is in communication with the first client robot and a second client robot, wherein the first client robot has a first sensing capability and the second client robot has a second sensing capability that is different than the first sensing capability, wherein the sensory data is captured by way of the first sensing capability of the first client robot, wherein the first client robot has a first functionality and the second client robot has a second functionality that is different than the first functionality, wherein the sensory data is relevant to the second functionality of the second client robot;

providing at least a portion of the sensory data captured by the first client robot as a first input to the second client robot, wherein the portion of the sensory data is relevant to the second functionality of the second client robot;

receiving feedback from the second client robot based on the first input; and

commanding the second client robot to perform a task by way of the second functionality based on the feedback and the portion of the sensory data captured by the first client robot.

9. The non-transitory computer readable memory of claim 8, wherein the operations further comprise:

receiving further sensory data from the first client robot; and

commanding the first client robot to perform an additional task based on the further sensory data.

10. The non-transitory computer readable memory of claim 8, wherein each of the first client robot and the second client robot include at least one sensor comprising one or more of an image capture device, an acoustic sensor device, and an electronic data acquisition device.

11. The non-transitory computer readable memory of claim 8, wherein the first sensing capability is related to capturing environment sensory data associated with a condition of an environment of the first client robot, and wherein the second sensing capability of the second client robot is related to sensing state of a device configured to adjust the condition of the environment of the first client robot.

12. The non-transitory computer readable memory of claim 8, wherein the operations further comprise:

receiving respective sensory data from the second client robot based on the commanded task, wherein the respective sensory data is captured by the second client robot by way of the second sensing capability; and

in response to the receiving the respective sensory data, commanding the second client robot to provide a second input to the first client robot indicating performance of the commanded task.